

Dataflow Graphs as Matrices and Programming with Higher-order Matrix Elements

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Abstract

We consider dataflow architecture for two classes of computations which admit taking linear combinations of execution runs: probabilistic sampling and generalized animation. We improve the earlier technique of almost continuous program transformations by adopting a discipline of bipartite graphs linking nodes obtained via general transformations and nodes obtained via linear transformations which makes it possible to develop and evolve dataflow programs over these classes of computations by continuous program transformations. The use of bipartite graphs allows us to represent the dataflow programs from this class as matrices of real numbers and evolve and modify programs by continuous change of these numbers.

We develop a formalism for higher-order dataflow programming for this class of dataflow graphs based on the higher-order matrix elements. Some of our software experiments are briefly discussed.

1 Introduction

Because probabilistic sampling and generalized animation are both stream-based, dataflow programming is a natural framework for this situation. Earlier we were able to leverage the ability to take linear combinations of execution runs to obtain the notion of *almost continuous transformation* of dataflow programs [1].

There were three main sources of *benign discontinuities* in [1]: addition of new subgraphs via an operation of *limited deep copy*, insertion of a new vertex and an edge during the first stage of *S-insert*, and insertion of an edge during the second stage of *S-insert*.

We now allow to decorate subgraphs with weights and require that new subgraphs created by limited deep copy appear initially with zero weight subject to subsequent continuous evolution.

We also introduce the discipline of arranging and linking vertices as a bipartite graph, namely that general transforms of fixed arity must point only at linear transforms of unlimited arity, and vice versa.

This allows to eliminate the benign discontinuities mentioned above and obtain *continuous program transformations*.

1.1 Dataflow Graphs as Matrices

It is convenient to have a situation where for any trajectory of program development or evolution all parts of the program which might emerge preexist in a silent way.

The discipline of bipartite graphs actually makes this possible. We fix a particular *signature* by taking a finite number of operations, each with its own fixed finite non-negative arity.

We take a countable number of copies of each *template operation* from the signature. Then we have a countable set of inputs of those operations, Y_j , and a countable set of their outputs, X_i .

Associate with each Y_j a linear combination of all X_i with real coefficients a_{ij} . We require that no more than finite number of elements of the matrix (a_{ij}) are nonzero.

We often impose additional conditions, e.g. we often require that all a_{ij} are nonnegative, and that the sum of elements a_{ij} associated with a particular matrix column Y_j does not exceed 1.

Thus we have a countable-sized program, namely a countable dataflow graph, all but a finite part of which is suppressed by zero coefficients. Any finite dataflow graph over a particular signature can be embedded into a universal countable dataflow graph over this signature in this fashion.

Hence we represent programs over a fixed signature as countable-sized real-valued matrices with no more than finite number of nonzero elements, and any program evolution would be a trajectory in this space of matrices.

1.2 Multiple Types of Data Streams

Originally this construction was envisioned for the situation when each node X_i and Y_j has a data stream of the same type, and all these streams are equipped with the same meaningful addition operation [1].

The most important case here is when these are streams of real numbers which can be considered as one-point generalized animations.

However, we might want to consider situations when there are multiple stream types associated with nodes. Consider a situation when Y_j and X_i are of different types. If $a_{ij} = 0$, this is fine, because then $a_{ij} \cdot X_i$ does not affect Y_j . If there is a default adapter T_{ij} between these types, then other values of a_{ij} are allowed, and $a_{ij} \cdot T_{ij}(X_i)$ is contributed to the sum. Otherwise the condition $a_{ij} = 0$ has to be enforced (a_{ij} are clamped at zero).

1.3 Multiple Types of Addition

One might want to also consider a situation where more than one meaningful addition operation is possible within the same program (e.g. point-wise addition of generalized animations and stochastic sum of the streams of probabilistic samples).

(Note that these additions are different from template operations: additions have unlimited arity and map infinite tuples of X 's to Y 's, and template operations have finite fixed nonnegative arity and map finite tuples of Y 's to X 's.)

In the case of multiple types of addition, each input Y_j of a template operation from the signature needs to be marked with the type of the addition operation it uses. If necessary, similar template operations with different addition types should be included in the signature separately.

One would typically include an identity transform for every type of data stream and for every type of addition applicable to this particular type of data stream in order to provide a capability to group the sums hierarchically.

1.4 String-based Indices

Rather than indexing our countable sets $\{X_i\}$ and $\{Y_j\}$ with numbers we are going to fix an alphabet and to index them with strings from that alphabet. Of course, letters can be considered as digits in an appropriate base, and strings as the corresponding natural numbers, but by indexing with strings we are trying to de-emphasize the order associated with this natural-numbers-based interpretation and to encourage an implementation of sparse arrays based on dictionaries (hash tables), with the expectation that zero elements of arrays and matrices would typically be omitted from their respective dictionaries.

In order to maintain our convention that the association between a particular X_j and its template operation is fixed, and that the association between X_j and its corresponding arguments $Y_{k_1}, \dots, Y_{k_{n_j}}$ ($n_j \geq 0$) is fixed and that all flexibility is concentrated solely in the values a_{ij} we adopt the following naming conventions.

We call a multiset (bag) of strings *prefix-free* if none of the strings in that multiset is a prefix of another string in that multiset. (Note that a prefix-free multiset cannot have multiple occurrences of the same string.) All template operations are given string names in such a way that the multiset consisting of all these names and the string '*arg*' is prefix-free. A node Y_j is indexed with a string j which starts with the name of the template operation associated with this node. We say that the string j is the name of Y_j . A node X_i which is one of the arguments for Y_j is indexed with the string i which is obtained by concatenating the prefix '*arg1*' ('*arg2*' etc.) with the name of Y_j . We say that the string i is the name of X_i .

1.5 Higher-order Programming

Because matrices, their columns, and their elements are vectors themselves, this is a platform with a variety of opportunities to create techniques for higher-order programming.

In this text we focus on one particular avenue for doing so, and this approach is centered around making elements a_{ij} higher-order (see Section 2).

To quote from Section 1.1 of [2] “A lot of expressive power of this architecture comes from the ability to have non-standard secondary structures on the set of points. Points can be associated with vertices or edges of a graph, grammar rules, etc. One should be able to formulate mechanisms of higher-order animation programming via variable illumination of elements of such structures.”

What is being done in the present paper is an instance of this approach.

A more precise mathematical description of the way this kind of computational engine functions is in Section 3.

Our first series of exercises in matrix-based dataflow programming which have been open-sourced simultaneously with the release of this preprint is described in Section 4.

2 Higher-order Matrix Elements

2.1 Degrees of Order

Here we classify varieties of a_{ij} .

2.1.1 Not Properly Higher-order Elements

A not properly higher-order element a_{ij} is not associated with a stream of any particular node X_k .

Zero elements (zero-order). These coefficients are zero and are not typically included in the dictionaries implementing the matrix or its columns.

First-order elements. Constant elements of the matrix (a_{ij}) are called first-order elements.

Variable elements (first-and-a-half order, sesquialteral-order elements). Elements of the matrix (a_{ij}) which vary with time belong to this class. Our exercises in higher-order dataflow have belonged to this class so far.

2.1.2 Properly Higher-order Elements

A properly higher-order element is associated with a datastream of a particular node X_k . The three types above are still representable with higher-order elements. When a node is not turned on (and typically is not in the appropriate dictionary), this is the case of zero-order element. When a node is constant value with no arguments, this is the case of first-order matrix element. When a node is a variable stream, but does not have argument nodes (so we are talking about a predefined/external variable stream), this is the case of sesquialteral-order element.

Specialized higher-order elements. When a node X_k is computed by a template operation with at least one argument, this is the case of a higher-order element. We call it specialized, because the operation which computes this element is fixed, although it can be controlled via its argument(s). Evaluation of such an operation is immediately effective, i.e. the newly computed coefficient is then immediately used to compute the appropriate linear combination.

Fully higher-order elements. In this case the node X_k is computed by a template operation which is the identity transform (one of the identity transforms, if multiple types of addition of streams of reals are included in the signature). In this case, the value in question can be computed in a very flexible manner from any linear combination of any transformations. However, the value is essentially computed on the “downswing” using the previous values of (a_{ij}) , and becomes the new effective value of the matrix only after the identity transform is applied to it. So if one needs to implement changing the a_{ij} via a particular specialized template operation, a one-cycle delay is involved before the new value of a_{ij} goes via a linear combination and via an identity transform and becomes effective.

2.2 Embedding the Set of Matrix Coefficient Indices into the Set of Column Indices

An interesting question is whether one can have all matrix elements to be properly higher-order elements. The answer is “yes”, and it is essentially based on the countability of the union of countable sets. This countability allows us to take the set of indices of matrix coefficients, (ij) , and embed it into the set of indices of matrix columns, j .

Here we are going to give an example of such an embedding which is sufficiently detailed to enable computer implementation.

Without properly higher-order matrix elements, it was possible to avoid giving unique names for matrix elements. For example, one could represent matrix columns as separate dictionaries and then just use the row names for matrix elements, like we do in the example of Section 4.

With properly higher-order matrix elements one needs unique names for matrix elements. We start with the naming scheme for columns and rows given in Section 1.4 and given the name N_j for column j and the name M_i for row i , we define the name for the matrix element (ij) as concatenation $'(+N_j+)' \# ('+M_i+)'$. Now we should just reserve parentheses for the use within the names of matrix elements only, but not within the “originally present names”, and this should be enough to avoid the name clashes.

3 A More Precise Description of the Abstract Machine

We only describe the machine for the situation where all nodes are streams of reals, and where one kind of addition operation exists with the sum being component-wise addition. It is not difficult to generalize appropriately.

Define an alphabet Σ which does not contain parentheses and the number sign, $'()^\#$.

Denote the set of all finite strings over Σ as Σ^* .

Define an operation as a tuple F containing name (a string $N_F \in \Sigma^*$), arity (a non-negative integer A_F), and a mathematical function $f_F : \mathbb{R}^{A_F} \rightarrow \mathbb{R}$ (if A_F is zero, f_F is simply a real number).

Define a signature as a finite set of operations, $S = \{F_1, \dots, F_n\}$.

We require that the multiset $\{N_{F_1}, \dots, N_{F_n}, 'arg'\}$ is prefix-free per Section 1.4.

We take F_1 to be the identity operation, $\langle 'id', 1, x \mapsto x \rangle$.

3.1 Abstract Machine Without Properly Higher-order Matrix Elements

The first case we consider is the case of sesquialteral-order matrix elements, which will be further illustrated by the example in Section 4.

We introduce the partially defined map Op from Σ^* to S (operations) and two partially defined maps X and Y from Σ^* to $\mathbb{N} \rightarrow \mathbb{R}$ (data streams).

We denote string concatenation with $+$ and string representation of a non-negative integer k as $str(k)$.

For $w \in \Sigma^*$ and for every $F_m \in S$ introduce $i = N_{F_m} + ' + w$. For all such i , $Op(i)$ and $X(i)$ (denoted as X_i) are defined and $Op(i) = F_m$.

For all such i , for all $k \in \{1, \dots, A_{F_m}\}$, introduce $j = 'arg' + str(k) + ' + i$. For all such j , $Y(j)$ (denoted as Y_j) is defined.

Now we have a dataflow graph representing the machine, and we need to define the values of data streams $\mathbb{N} \rightarrow \mathbb{R}$ associated with graph nodes X_i and Y_j , which will define how the machine works.

Time starts with value 0 and increases by 1 at each machine step. For every i and j defined above there is a stream of values $\mathbb{N} \rightarrow \mathbb{R}$ associated with a_{ij} . Given that we are considering the case of sesquialteral-order matrix elements, we assume that streams associated with a_{ij} are external to the program and are just generated by their externally programmed generators.

At time 0 we start with all X_i and Y_j being the streams of one element, which equals to 0 for all those streams. The values of a_{ij} at the moment 0 are not important at this level of consideration, because we only give a mathematical definition in this section and ignore the question of sparseness as an implementation detail (of course, nothing would even fit a finite machine without this implementation detail).

Then given streams X_i , Y_j , and a_{ij} of length t , here is how the components $t + 1$ are defined (that is, computed by the abstract machine; so this is a definition by induction with respect to time, and this definition describes how the machine works).

Step 1. First, for all i , the value of X_i at time $t + 1$ is computed as follows. One considers $Op(i)$, and for all $k \in \{1, \dots, A_{Op(i)}\}$ and $j_k = 'arg' + str(k) + ' + i$ one takes the value y_{j_k} as being the value of the stream Y_{j_k} at moment t . The value of X_i at time $t + 1$ then is computed (defined) as $f_{Op(i)}(y_{j_1}, \dots, y_{j_{A_{Op(i)}}})$.

Step 2. Then the values of streams corresponding to a_{ij} at the moment $t + 1$ are externally generated. The condition that only a finite number of those are different from 0 at the moment $t + 1$ is observed.

Step 3. Finally, for all j , the values of streams associated with Y_j at the moment $t + 1$ are computed as the linear combinations $\sum_i a_{ij} \cdot X_i$, where a_{ij} and X_i are the values of the corresponding data streams at the moment $t + 1$.

3.2 A More Abstract View

Here is a more abstract way to describe what is going on in the previous subsection.

There are two (in general, countably dimensional) vector spaces X and Y . There is a fixed non-linear function $F : Y \rightarrow X$ induced by the signature. There is a family of linear transformations $L_t : X \rightarrow Y$ parametrized with time (this corresponds to sesquialteral-order of L).

We define streams of vectors x_t, y_t from X, Y parametrized with time by induction over time. We define x_0 and y_0 to be zero vectors and L_0 is irrelevant.

At time $t + 1$, first we take $x_{t+1} = F(y(t))$, then we note the current L_{t+1} and take $y_{t+1} = L_{t+1}(x_{t+1})$.

In the subsection which follows we use the embedding from Section 2.2 to incorporate L into X .

Then at time $t + 1$ we take $x_{t+1} = F(y(t))$ and among other things this yields L_{t+1} . Then we take $y_{t+1} = L_{t+1}(x_{t+1})$.

We occasionally parametrize F as F_t as well, to allow the dynamic tuning of the system and to account for the stochastic factors in randomized template operations.

3.3 Abstract Machine with all Fully Higher-order Matrix Elements

Here we modify the construction of Section 3.1 in order to deliver what was promised at the end of the previous subsection. We start with sets of names $I = \{i\}$ and $J = \{j\}$ defined in Section 3.1.

Then we define $I_0 = I$ and $J_0 = J$, and organize the induction as follows.

Given I_n and J_n we first use the scheme from Section 2.2 to define set of names of matrix elements:

$$A_{n+1} = \{(' + j + ') \# (' + i + ') \mid i \in I_n, j \in J_n\}.$$

Then we use the fact that our signature has the identity operation and define $I_{n+1} = I \cup \{id' + a \mid a \in A_{n+1}\}$ and $J_{n+1} = J \cup \{arg1 id' + a \mid a \in A_{n+1}\}$.

Now consider the limit of this process, $I_\infty = \bigcup I_n$ and $J_\infty = \bigcup J_n$.

Then this limits is the fixed point of this process, namely that if we define $A_\infty = \{(' + j + ') \# (' + i + ') \mid i \in I_\infty, j \in J_\infty\}$, then $I_\infty = I \cup \{id' + a \mid a \in A_\infty\}$ and $J_\infty = J \cup \{arg1 id' + a \mid a \in A_\infty\}$.

Now the steps at the end of Section 3.1 are modified as follows. Performing Step 1 yields values of streams corresponding to a_{ij} at the moment $t + 1$. If only finite number of those values are different from 0 at the moment t , then only a finite number of them would be different from 0 at the moment $t + 1$ (for the detailed explanation of the reasons for that see the last paragraph of the next subsection).

Then we can go ahead and perform Step 3.

3.4 Sparseness Considerations

The discussion of the abstract machines would not be complete without discussing how to keep the amount of computations at each step finite (as, if possible, minimal).

For the setup of Section 3.1, the requirement is that if a matrix element a_{ij} is nonzero, then its linear combination needs to be evaluated and the template operation computing X_i and the template operation using Y_j as an argument both need to be evaluated, so the appropriate nodes should be included into the dictionaries in question. When for a template operation with inputs Y_1, \dots, Y_k and output X_i all matrix elements related to nodes Y_1, \dots, Y_k and output X_i are zero, it is not recommended to evaluate such a template operation or to include the nodes in question into dictionaries (although doing so is legal).

This means that when a_{ij} becomes nonzero for the first time, the Y_j node and the template operation using this node as an input together with the other vertices of this template operation must be added to the appropriate dictionaries, if it is not already there. Similarly, the X_i node and the template operation computing it together with the other vertices of that template operation must be added to the appropriate dictionaries, if it is not already there, and moreover, it needs to be retroactively computed (by evaluating

the corresponding template operation with zero values of its arguments) before the linear combination using a_{ij} can be evaluated.

The same considerations are valid for the setup of Section 3.3. At any given moment of time we only have a finite number of operations computing a_{ij} being in the dictionaries and subject to being evaluated. So only finite number of them might become nonzero for the first time at any given time moment. Hence no more than a finite number of new nodes need to be added to the dictionaries on each time step.

4 A Simple Example

This architecture is applicable to probabilistic sampling and to generalized animation. We created an open source software prototype demonstrating the use of those techniques for streams of real numbers implementing a family of continuous cellular automata.

The software and associated videos have been released simultaneously with this preprint as `aug_20_15_experiment` in the Project Fluid repository [3].

Note that we cannot make these video previews quite faithful; video compression software introduces some distortion at the initial stage of uploading a video, then it notices the problems with quality and offers to automatically fix lighting, the overall result might be worse in some aspects and better in some other aspects than the video natively produced by the software.

This is an example of a situation when a matrix-based dataflow program is used in combination with other software. In this particular case, the video output from the dataflow program is being passed through an external lighting-enhancing software.

The set of template operations for this series of experiments is very simple: zero-arity constants, `black` and `white` (-1 and 1), and a unary randomized propagator, copying the value of its input Y_j to its output X_i with probability p (a typical value of which in this series of experiments is 0.995) and setting the output to zero otherwise. The setup is essentially that of Section 3.1, except that we allow several copies of a template operation to share an input when convenient (mathematically this is equivalent to constraining several columns of a matrix to be the same).

In this series of experiments we use the dynamic nature of matrix elements very sparingly, first having the weights concentrated on the output of the constants (initialization phase) and then switching it (continuously, or, as in this series of experiments, abruptly) to the output of the randomized propagators forming a structure determining the connectivity of the continuous cellular automaton in question. This architecture also allows to continuously morph between a variety of connectivity structures, but we have left this as a simple exercise to the reader.

We are observing a variety of emerging Turing structures with interesting dynamics in this series of experiments, depending mostly on the connectivity pattern, and also on the initialization configuration. In the spirit of non-equilibrium thermodynamics, even when one starts with a uniform initial pattern (all black or all white), the structures first emerge driven by the randomized propagators and by the connectivity pattern, and then fade out to gray (zero value, the thermodynamic equilibrium). If one includes the amplification during the visualization stage (scaling the brightness of the image so that the maximal absolute value of a rendered point reaches 1), then one can observe that the meaningful fine structures of the dynamic patterns tend to persist indefinitely (in some cases the main motive is preserved, in other cases the pattern is shifting and evolving unpredictably).

See the Fluid repository for further details.

4.1 An Example with Properly Higher-order Matrix Elements

The `aug_24_15_experiment` implements the same example using fully higher-order elements (all but two matrix elements in that experiment are fully higher-order, while two of its elements are not properly higher-order, and their change is controlled from the outside).

This experiment also features pause/resume facility controlled by the mouse key and the space bar, improved brightness amplification, and an adjustment mechanism to stabilize the values and prevent their relaxation to zero.

We recommend that the reader uses this experiment to further explore the system.

5 Conclusion

This architecture allows us to evolve dataflow programs in continuous fashion while those evolving programs are running. This makes it possible to sample continuous trajectories in the space of dataflow programs, in addition to the usual practices of sampling the syntax trees of programs.

The representation of programs as matrices of real numbers makes the task of program learning more similar to the task of machine learning for more narrow and conventional classes of models.

One way to introduce some higher-order mechanisms in dataflow programming (and in neural networks) is via letting any particular data stream to propagate along multiple directions in the graph, and to dynamically control the actual directions of propagation by setting the multipliers along some of those paths to zero.

A somewhat unexpected result of the present preprint is that this particular higher-order mechanism seems to be universal: all higher-order programming for a given class of dataflow graphs over datastreams with linear combinations of execution runs built on top of a fixed signature of template operations seems to be expressible via setting multipliers along the paths of data propagation (in particular, setting all but the finite number of them to zero).

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